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Patent Abstracts of Japan
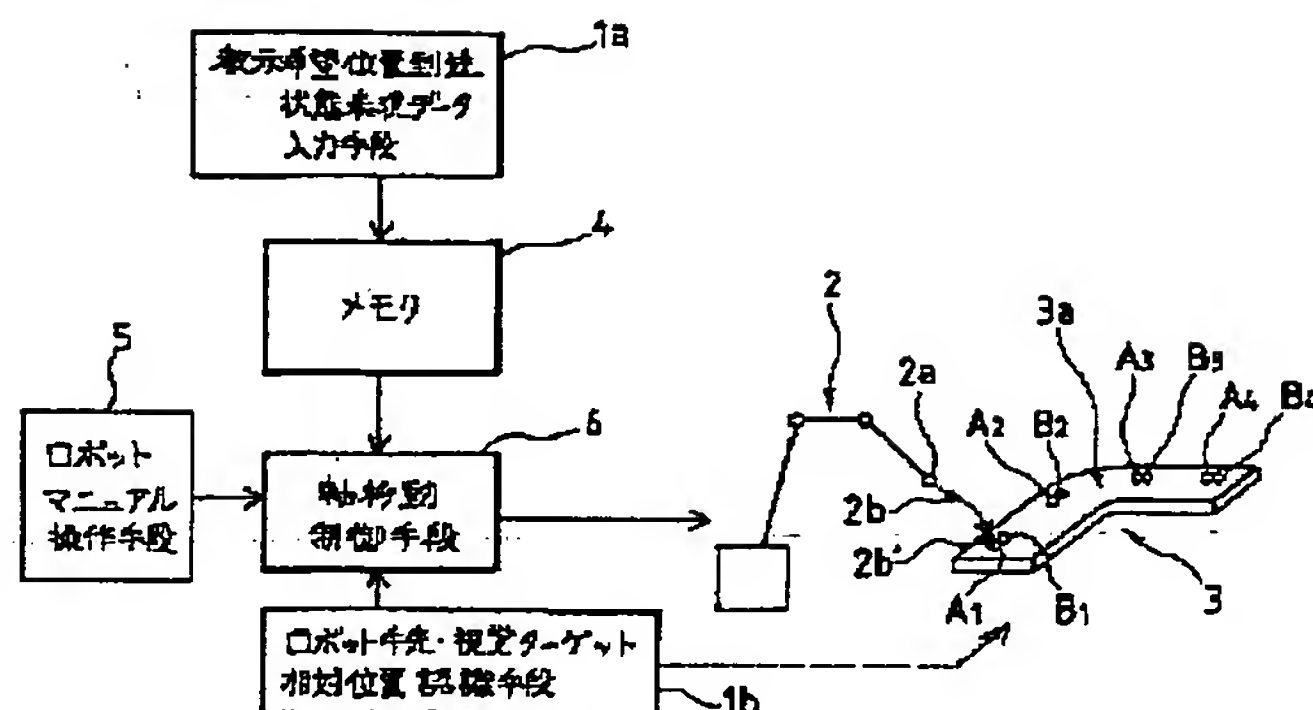
ABSTRACT : PROBLEM TO BE SOLVED: To make instructing operation, which makes good use of a visual sensor and a visual target, efficient.

SOLUTION: A desired instruction position arrival state representation data input means 1a which makes good use of the visual sensor previously inputs data, representing the relative position relation between the visual target B_1 and a robot arm tip 2a in a state 2b' wherein the TCP 2b of the robot 2 has finished moving to a desired instruction position A_1, etc., to a memory 4. An operator operates a robot manual operation means 5 such as a jog feed button to make a shaft movement control means 6 control respective shafts, thereby starting jog movement. Further, the mode is shifted from the job movement mode to an autonomous movement mode and the TCP 2b is autonomously moved to the desired instruction position A_1, etc. Control over the autonomous movement is performed on the basis of the desired instruction position arrival state representation data and data obtained by a robot arm tip-visual target relative position recognizing means 1b which utilizes the visual sensor. A target means is actualized by a mark coordinate system or light spot projection means.